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(54) IMPROVEMENTS IN OR RELATING TO ULTRASONIC
 EXAMINATION APPARATUS

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(71) We, SONICAID LIMITED, a British Company of Hook Lane, Nyetimber, Bognor Regis, Sussex PO21 3PA, do hereby declare the invention, for which we pray that a patent may be granted to us, and the method by which it is to be performed, to be particularly described in and by the following statement:—

This invention relates to apparatus for the ultrasonic examination of bodies having non-planar surfaces. One particular application of the invention is in a three-dimensional ultrasonic pulse echo scanner for medical diagnosis.

Ultrasonic examination apparatus including a probe mounted so that it is capable of translational movements along three coordinate axes and of two rotary movements has been described in United Kingdom Patent Specification No. 1,212,349 and the present invention is particularly applicable to apparatus including a probe mounted in this manner. In the particular system described in the said Patent Specification, signals defining the instantaneous position and attitude of the probe are derived by means of potentiometers and it is a particular object of the present invention to provide a system in which such positional signals can be derived without the use of potentiometers.

The invention consists in apparatus for the ultrasonic examination of bodies having non-planar surfaces, including an ultrasonic probe mounted on one end of a boom so that it is movable around the body to be examined, at least one wave transmitter mounted on the opposite end of the boom in such a way that it follows the movements of said probe, and a plurality of wave receivers arranged to receive wave energy from said wave transmitter or transmitters and convert it into electrical signals representing the instantaneous position of the probe in a coordinate system.

Preferably the probe is longitudinally extending and directs a beam of ultrasonic pulses into the body and receives reflected pulses from the body and means are provided to produce electrical signals defining not only the instantaneous position of a point on the longitudinal axis of the probe but also the instantaneous attitude of said axis with reference to the coordinate system. In one embodiment the probe is mounted on the boom so that the probe is pivotable about first and second mutually perpendicular axes intersecting in a point fixed with reference to the boom, and the boom is mounted on a column so that the boom is pivotable about a third axis perpendicular to the axis of the boom and a fourth axis perpendicular to said third axis, said third and fourth axes intersecting in a point fixed with reference to the column.

Preferably the boom is mounted so that it has limited rotational freedom about its own axis.

In another embodiment the probe is mounted on the boom so that the probe is pivotable about at least one axis fixed with reference to the boom, said boom being mounted on a column so that the boom has limited rotational freedom about the axis of the boom and is also pivotable about a third axis perpendicular to the axis of the boom and a fourth axis perpendicular to said third axis, said third and fourth axes intersecting in a point fixed with reference to the column.

The electrical signals defining the position and attitude of the probe are preferably produced by apparatus including two ultrasonic wave transmitters mounted and controlled so that they follow the angular movements of the probe relative to the boom and also follow the movements of the boom relative to the column. Three ultrasonic transducers are arranged to receive wave energy from the two transmitters

and convert said energy into said electrical signals. The transmitters may also be caused to follow the movement of the column along its horizontal axis, but it is simpler for this particular motion to be followed by arranging that the receiving surface of one of the transducers is perpendicular to the direction of said horizontal axis and by causing this transducer to copy the movement of the column.

Preferably the angular movements of the line joining the wave transmitters are equal to the angular movements of the probe, but the translational movements of the transmitters are proportional to the translational movements of the probe on a reduced scale.

Preferably, the two wave transmitters are mounted in a tank containing an acoustically transmissive fluid. The fluid is preferably a liquid, but in certain circumstances may be a gas or air. The transmitters may be in the form of beads designed to produce spherical acoustic wave trains. Each of the transducers mounted in the tank may consist of a single flat plate of a coplanar mosaic of such plates, preferably electrically connected in series. The overall dimensions of the plates or mosaics are such that any perpendicular erected through either bead on to the plane of one of the transducer surfaces always lies within the boundary of the respective plate or mosaic within the limits of motion of the ultrasonic probe and the corresponding motion of the transmitters. As already stated, one of the plates or mosaics may be arranged for motion perpendicular to its plane, such motion being proportional to—and in inverse direction to—the motion which would otherwise be applied to the transmitters.

Means are provided for generating short bursts of electrical energy, which are applied to the two transmitters in order to produce the spherical wave trains of ultrasonic energy. Means are also provided to generate electrical signals proportional to the elapsed time between the transmission of the wave train from each bead and reception of the wave train by each receiver, each such signal being proportional to the perpendicular distance from the respective transmitter to a respective one of the receiver surfaces. The signals representing the position of the probe in space may be derived solely from the signals received from the first transmitter or may be derived by combining these signals with those received from the second transmitter. The signals representing the attitude of the probe in space are always derived from a combination of the signals received from the two transmitters.

The wave transmitters may be caused to follow the translational movement of the

probe by mounting them on wands carried on a rearward continuation of the boom carrying the probe, the length of the continuation being, for example, one-tenth of the length of the boom itself. It will be seen that with such an arrangement the free end of the continuation will perform movements which are reverse images of the movements of the forward end of the boom on a scale reduced by a factor of one to ten.

Preferably, the intersection of the first and second mutually perpendicular axes about which the probe is pivotable is spaced from the longitudinal axis of the boom and the longitudinal axis of the probe may also be displaced from this intersection along said first axis. The wands carrying the two beads at their free ends may project from a shaft which is rotatable in a bearing. One of the wands is straight and perpendicular to the shaft and the distance between the shaft and the centre of the bead carried by this wand corresponds to the distance between said first axis and the operative face of the ultrasonic transducer in the probe. Accordingly, in the example being considered, the distance between the shaft and the bead is one tenth of the distance between the first axis and the said face. The other wand is cranked and is arranged to support the second bead so that it is spaced from the first bead, the line joining the two beads being perpendicular to the shaft. Thus the position of the second bead corresponds to a point on the directivity axis of the beam from the transducer in the probe.

The bearing in which the shaft is rotatable is fixed in a member which is rotatable about an axis which intersects the axis of the shaft at right angles thereto. The axis of rotation of this member is spaced from the plane containing the line joining the beads by a distance equal to one tenth of the distance between the second axis and the longitudinal axis of the probe. The axis of rotation of the member is also spaced from the longitudinal axis of the boom and its extension by one tenth of the distance between the second axis and the longitudinal axis of the boom. For this purpose the rearward end of the extension may be cranked.

The rotational movements of the probe about the first and second axes are preferably transmitted to the shaft and the rotatable member by means of cables located inside the boom.

One method of performing the invention will now be described with reference to the accompanying diagrammatic drawings, in which:—

Figure 1 is a perspective view of ultrasonic scanning apparatus in accordance

with the invention,

Figure 2 is a perspective view, on an enlarged scale, showing the mounting of the ultrasonic probe used in the apparatus 5 illustrated in Figure 1,

Figure 3 is a side view partly in perspective, on an enlarged scale, of the probe and mounting arrangement illustrated in Figure 2,

10 Figure 4 is a perspective view partly broken away to show the interior of a measuring device used in the apparatus illustrated in Figure 1,

Figure 5 is a side view on an enlarged 15 scale of part of the measuring device illustrated in Figure 4.

Figure 6 is a plan view of the part of the measuring device shown in Figure 5,

Figure 7 is an end view rotated through 20 90° and partly in section of the arrangement for mounting the supporting column of the apparatus shown in Figure 1,

Figure 8 is a sectional side view of the braking arrangement for the apparatus 25 shown in Figure 1,

Figure 9 is a diagrammatic illustration of the means for transferring movement of the supporting column to the measuring device illustrated in Figure 4,

30 Figure 10 is a perspective view of the arrangement for mounting the boom on its supporting column,

Figure 11 is a plan view partly in section of a part of the mounting arrange- 35 ment shown in Figure 10,

Figure 12 is a block diagram of the electrical equipment used in the apparatus illustrated in Figures 1 to 11, and

40 Figure 13 is a more detailed block diagram of part of the electrical apparatus illustrated in Figure 12.

The apparatus shown in Figure 1 includes a base 1, which is manoeuvrable on 45 caster wheels, parts of two of which can be seen at 2 and 3. When the apparatus has been moved to the desired position in relation to a patient's couch 4, it is held stationary by means of braking pads 5, controlled by twist-grips 6.

50 A supporting column 7 is movable on rails relative to the base 1 and at the head of the column is a measuring device 8. At one end of the device 8 is a boom 10 supported in a gimbal mounting 9. This 55 boom is pivotable about its own axis as indicated by the arrow 11, about a horizontal axis as indicated by the arrow 12, and about a substantially vertical axis as indicated by the arrow 13. The horizontal 60 and vertical axes are fixed with reference to the column 7, being located in the gimbal system 9.

Mounted on the free end of the boom 10 is a head 14, carrying a gearbox 15, 65 which is rotatable about an axis 16 as indi-

cated by the arrow 17. An ultrasonic probe 18 is pivotable about an axis 19 in the gearbox 15 as indicated by the arrow 20. Movements of the gearbox 15 about axis 16 are transmitted to the measuring device 8 70 by cables 21 which are secured to a pulley 30 fixed to rotate with the gearbox 15 and pass around pulleys 22 and along the interior of the boom 10. Movement of the probe 18 about the axis 19 is also trans- 75 mitted to the measuring device 8 by further cables passing along the boom 10 as will be described with reference to Figures 2 and 3.

It will be seen that a cam-shaped collar 80 9 is fitted on the boom 10 and this collar cooperates with a slot 160 in the front wall of the housing 161 of the measuring device 8 to limit the movement of the boom 10 in all its directions of freedom. 85

Figure 2 shows the head 14 in more detail and also shows the cables 23 which transmit the motion of the probe 18 about the axis 19 to the measuring device 8. The probe 18 is removably secured to a saddle 90 24 by means of a screw 25 and, as can be seen from Figure 3, the saddle is rotatable on a shaft 25 carried in bearings in the gearbox 15. Secured to the shaft 25 is a bevel gear 26, which meshes with a 95 further bevel 27 carried on a shaft 28, to which is secured a pulley 29. The cables 23 pass around the pulley 29 and as a result any motion of the probe about the axis 19 causes one of the cables 23 to move 100 in one direction along the boom 10, while the other cables 23 moves in the opposite direction. The pulley 30, which is not visible in Figures 2 or 3 is secured to a further shaft which is fixed to the gearbox 105 15; consequently movement of the gearbox about the axis 16 causes rotation of the pulley 30 which once again causes one of the cables 21 to move in one direction along the boom 10, while the other cable 21 110 moves in the opposite direction.

Figure 4 is a general view of the measuring device 8 and it will be seen that this includes a measuring tank 31 enclosed in the housing 161. The measuring tank is 115 filled with oil, which is a good medium for the transmission of ultrasonic waves. The tank is lined with an acoustic material 32 designed to absorb ultrasonic waves and prevent reflections. The boom 10 projects 120 into the tank through an oil-tight gland (not shown). A cranked arm 33 is mounted on the inner end of the boom and carries wands 34 and 35 on which are mounted ultrasonic transmitters 36 and 37 in the 125 form of beads designed to produce spherical acoustic wave trains. In the particular arrangement illustrated the distance between the outer end of the boom 10 and the intersection of the pivot axes of the gimbal 130

system 9 is ten times the distance between the said intersection and the inner end of the boom. Thus, it will be seen that the distance through which the outer end of the boom moves, when it is pivoted about either of the gimbal axes, is always ten times the distance through which the inner end of the boom moves.

The two wands 34 and 35 are mounted on a shaft 38, which can be seen more clearly in Figures 5 and 6. This shaft is rotatably mounted in bearings 40 in an angle member 39 and carries a bevel gear 41 which meshes with a further bevel gear 42 fixed to a shaft 43 rotatable in the cranked arm 33. Fixed to the outer end of the shaft 43 is a pulley 44 connected by a belt 45 to a further pulley 46, which is rotatable in bearings in the boom 10. A further pulley (not visible in the drawings) is rotatable with the pulley 44 and the two cables 23 are connected to this pulley, so that any angular motion of the probe 18 about the axis 19 results in equal angular motion of the shaft 38 about its axis.

The angle member 39 is rotatable about the axis of the shaft 43 and is connected to a pulley 47, which is connected by a belt 48 to a further pulley 49. A further pulley (not visible in the drawings) is rotatable with the pulley 49 and the two cables 21 are connected to this pulley so that any angular motion of the gearbox 15 about the axis 16 results in equal angular motion of the angle member 39 about the axis of the shaft 43.

Mounted in the tank 31 are three ultrasonic transducers, each consisting of a coplanar mosaic of flat plates electrically connected in series. One of the transducers 50 is mounted on one of the side walls of the tank; a second transducer 51 is mounted on the lid of the tank; and a third transducer 52 is mounted on a shaft 53, which is slidable through a bearing in the rear wall of the tank. A bellows 54 is fitted over the shaft to provide an oil seal. The transducer 52 is controlled so that it follows any motion of the column 7 in the base 1. For this purpose, the base 55 of the column 7 is provided with a shaft 56 carrying two pulleys 57 and 58 (Figure 9). A wire 59 which is secured at each end to the base 1, as shown at 60 and 61, is wrapped round the pulley 57, so that the shaft 56 is rotated as the pulley 57 moves along the wire. This rotation is coupled to a further wire 62, which passes up the column and around pulleys 63 and 64 to wrap around a further pulley 65. This pulley is fixedly mounted on a shaft 66, which also carries a pinnion 67. The pinnion 67 engages with a rack 68 on the shaft 53, so that any movement of the column 7 relative to the base 1 produces

corresponding movement of the transducer 52 relative to the tank 31. The diameters of the various pulleys and the number of teeth on the pinnion 67 are such that the distance through which the plate 52 moves is one tenth of the distance through which the column moves relative to the base.

The can-shaped collar 9 cooperates with the slot 160 to limit the movement of the boom 10, so that the wave transmitters 36 and 37 cannot be brought into contact with the three ultrasonic transducers 50, 51 and 52. The collar and the slot are shaped to allow the maximum possible movement under all conditions, since it will be understood that it is possible, for example, to depress the boom further about its horizontal axis when the boom is rotated so that the wands 34 and 35 are generally horizontal than when the wands are vertical as shown, for example, in Figure 4 of the drawings.

The mounting arrangements for the column 7 are shown particularly in Figure 7, from which it will be seen that the column runs on two rails 69 and 70 fixed in the base 1. The base 55 of the column 7 is provided with two triangular blocks 71 and 72, carrying a total of eight supporting wheels. Four of these wheels can be seen in Figure 7 at 73, 74, 75 and 76. The supporting wheels are individually adjustable, so that the column 7 travels backwards and forwards along the base 1 with a minimum of friction and a maximum of stability.

The arrangements for preventing movement of the base once it has been manoeuvred into the desired position are illustrated in detail in Figure 8, which shows how the pad 5 is controlled by rotation of the twist-grips 6. One end of a link 77 is connected by a pin 78 to a wheel 79 rotatable with the twist-grip 6. The other end of the link 77 is connected by a pin 80 to a pair of toggle levers 81 and 82. The drawing shows the toggle levers in full lines in the position in which the pad 5 is lowered and in dotted lines in the position in which the pad 5 is raised. As can be seen, the toggle lever 81 is pivotally mounted in the frame 83 at 84, while the toggle lever 82 is connected at 85 to a vertical shaft 86 slidable in bearings within the vertical part of the frame 83. The pad 5 is fitted to the lower end of the shaft 86 and a spring 87 is provided to assist in raising the pad. Rotation of the pad about the axis of the shaft 86 is prevented by a pin 88.

The manner in which the boom 10 is mounted in the tank 8 is illustrated in Figures 10 and 11. It will be seen that the boom is carried in a gimbal mounting including an outer cage 90, which is

pivotable relative to the tank about a horizontal axis, and an inner cage 91 which is pivotable relative to the outer cage about an axis perpendicular to said horizontal axis. The outer cage 90 rotates about two shafts such as that shown at 92 in Figure 11. Shaft 92 is fixed in a wall 93 of the tank and carries a bearing 94 fixed in the outer cage 90. Coil springs 95 and 96 are provided to support the weight of the boom 10, so that it can be readily moved about the said horizontal axis and will normally remain in any position to which it is set. The inner end of the coil spring 95 passes through a slot in a cup-shaped member 97, so that it is anchored to this member, which is secured to the wall 93 by means of countersunk screws such as that shown at 98. The outer end of the spring 95 is anchored on a pillar 99, one end of which is attached to a projecting portion 100 of the outer cage 90. The other end of this pillar is secured to a lever 101 secured to, or forming part of, a generally cylindrical member 102. The cylindrical member 102 has a flat base 103, which is urged towards the bottom of the cup-shaped member 97 by means of a helical spring 104. A friction washer 105 is interposed between the base 103 and the bottom of the cup 97. The spring 104 can be tightened by means of a nut 106 to provide the required degree of friction between the members 102 and 97. It will be seen that the member 102 rotates with the boom about the horizontal axis, while the cup 97 is stationary with respect to the tank 8. Accordingly, the friction washer 105 is operative to damp movements of the boom about the horizontal axis. The force applied to the boom by each of the coil springs 95 and 96 can be adjusted by removing the screws such as that shown at 98 and rotating the respective cup 97 about the axis of shaft 92. When the desired tension has been achieved, the screws, such as that shown at 98, are replaced and tightened. If desired, movement of the boom about the horizontal axis can be inhibited by means of an electromagnetic brake 162.

The inner cage 97 is rotatable about an axis defined by a rod 107 and it will be seen that movements about this axis are damped by means of a friction washer 108 urged against a flat surface of the outer cage 90 by means of a helical spring 109 and a nut 110.

The boom 10, apart from being pivotable about horizontal and vertical axes in the gimbal mounting, is also rotatable about its own axis and for this purpose is mounted in the inner cage 91 in a bearing 111. Suitable seals are provided to prevent the oil in the tank 8 from escaping through the bearing 111.

From the foregoing description it will be understood that the probe 18 is pivotable about two perpendicular axes 16 and 19 with respect to the boom 10, which is itself pivotable about two perpendicular axes and is also rotatable about its own axis. Further, the column 7 is movable linearly with respect to the base 1. These movements allow the probe 18 to be moved over the majority of the surface of the body of a patient lying on the couch 4 and in addition enable the beam of ultrasonic pulses from the probe to be directed in substantially any direction through the patient's body. All these movements of the probe are matched by corresponding movements of the two ultrasonic transducer beads 36 and 37. The bead 36 is mounted and controlled so that its position relative to the three transducers 50, 51 and 52 corresponds to the instantaneous position of the operative face of the transducer in a coordinate system fixed relative to the base 1. The bead 37 is so mounted and controlled that it represents a point on the axis of the ultrasonic beam transmitted by the probe. Thus, the instantaneous position of the operative face of the probe can be determined by measuring the respective distances between the bead 36 and the three transducers 50, 51 and 52, and the inclination of the directivity axis of the probe can be determined by measuring the inclination of the line joining the two beads 36 and 37 in each of three planes perpendicular to the three transducers 50, 51 and 52. This latter inclination can readily be measured by calculating the difference between the distances of the two beads from each of the three transducers. The system used for measuring the required distances is illustrated in Figures 12 and 13.

Referring first to Figure 12, it will be seen that a pulse generator 120 supplies pulses of ultrasonic energy through a variable attenuator 121 to the probe 18, which includes an ultrasonic transducer capable of acting both as a transmitter and as a receiver of ultrasonic energy. The reflected pulses received by the probe 18 are fed to an amplifier 122 and thence to a detector and signal processor 123, the output of which is applied to a terminal 154 and used to modulate the intensity of the beam of a cathode-ray-tube display system 124. The detector 123 is a zero-crossing detector and senses the instant at which the first cycle of the received damped sinusoid passes through zero. Such a detector is independent of system gain and is therefore superior to a simple leading edge detector. The amplification of the amplifier 122 is controlled by a gain control circuit 125 and the operation of the detector 123 is controlled by a gate circuit 126. A logic control and

timing system 127 has an output 128 which is applied to the generator 120, the gain control circuit 125 and the gate circuit 126.

The signals from the three transducers 50, 51 and 52 are applied to three individual time-base systems 129, 130 and 131, which are also all controlled by the logic system 127. The outputs of the three time-base systems are passed through two coordinates transformation networks 132 and 133, which are normally manually controlled. The output of the second coordinate transformation network is passed through a display selection system 134 to the deflector plates of the display system 124. As shown, this display system is a single cathode-ray tube, but it is to be understood that it can be replaced by a scan converter, with associated reading means. In either case, the display or storage surface can be divided into two regions displaced horizontally, and these regions arranged to present stereoscopic pairs of images. The display selection system can also be used to inject linear perspective correction into such an image or images. (See, for example, "Interactive Single-Entry-Point Scanning for Medical Diagnosis" by T. G. Brown and J. R. Greening, pages 208-213, Ultrasonics International 1973 Conference proceedings published by IPC Science and Technology Press Ltd. Guildford).

Each of the three time-base units may be, for example, as illustrated in Figure 13. In addition to the various parts of one of the time-base units, this figure also shows one of the three transducer plates, which may be, for example, the plate 50 and the two beads 36 and 37 together with a line 141 passing through the two beads and a notional pivot point 140. As already explained, this line corresponds to the directivity axis of the probe 18 and the direction of travel of the sound in the patient. The instantaneous distance of the bead 36 from the receiving surface of the plate 50 is shown as d_1 , while the bead 37 is at a distance d_2 from the surface of the plate 50. Thus, the difference between the two distances ($d_1 - d_2$) is proportional to the cosine of the angle α , which defines the inclination of the line 141 in the plane of the paper with respect to a line perpendicular to the plate 50. Thus, the difference is also a measure of the angle of inclination of the probe in one of the three perpendicular planes of the coordinate system, or, from another point of view, is a measure of the component of the sound pulse velocity in the patient along one of the three coordinate axes.

The logic system 127 has already been referred to and is common to all three time-base systems as well as to the re-

mainder of the system illustrated in Figure 12. Further, three pulse generators 142, 143 and 144 are common to the three time-base systems and this fact is indicated in the drawing by the dashed line inside each 70 of the respective blocks.

The two pulse generators 142 and 143 supply trains of ultrasonic pulses to the two beads 36 and 37 at intervals determined by the logic system 127. These pulses are received by the plate 50 after delays which are indicative of the distances d_1 and d_2 . When the logic system 127 causes the pulse generator 142 to apply a pulse to the bead 136, it also causes a digital counter 145 to start counting up. When the pulse from the bead 36 is received by the plate 50, it is applied to a detector 146, the output of which is used to stop the counter 145. Accordingly, the number registered by the counter indicates the time taken for the pulse to travel from the bead 36 to the plate 50 and hence is a measure of the distance d_1 . This number is transferred to, and stored in, a shift register 147. When the logic system triggers the pulse generator 143, it causes the counter 145 to commence counting down from the number previously registered. When the pulse from the bead 37 reaches the plate 50 and is received by the detector 146, the counter 145 is again stopped. Consequently, the number now registered by the counter represents $d_1 - d_2$. This number is transferred to, and stored in, a second shift register 148.

The number stored in the shift register 147 is converted to an analog signal in the digital-to-analog converter 153, and similarly the number stored in the shift register 148 is converted to an analog signal by the digital-to-analog converter 149. The output of the converter 149 controls an integrator 150, which produces a ramp signal, the slope of which is proportional to the signal from the converter 149, and hence is proportional to the component of the sound velocity in the patient along the particular coordinate axis. The output of the integrator 150 is added to the output of the converter 153 in a summing amplifier 151. The integrator 150 and the converter 153 are controlled by the logic circuits 127, so that the output 152 from the summing amplifier 151 is a ramp starting at a particular point in time at a level determined by d_1 and having a slope determined by d_2 . Thus, since d_1 is indicative of one component of the position of the operative face of the probe and d_2 is indicative of one component of the velocity of the transmitted pulse in the patient, the instantaneous value of the ramp is indicative of the point in the patient from which an echo is received. In this connection it is, of course, to be understood that, since the sound has to

travel from the operative face of the probe to the reflective surface and back to the probe, the level of the ramp increases at half the velocity of the sound in the patient.

5 The operation of the system will now be described on the assumption that it is already in operation. Thus, values of d1 and d1-d2 for each coordinate will be stored respectively in the shift registers 147 and 148 of the respective time-base units. 10 The pulse generator 120 is triggered by the logic circuit 127, so that a pulse of sound is transmitted into the patient and echoes are received and passed through the 15 amplifier 122 and the detector 123 to modulate the intensity of the beam in a cathode-ray-display system 124. The ramps from the output terminals 152 of the three time-base units are passed through the two 20 coordinate transformation networks 132 and 133, the operation of which can be ignored for the purpose of the present explanation, and are applied to the display selection system 134. In the simplest case this system 25 is used to select two of the ramps for application to the X and Y deflection plates of the cathode-ray-tube display system 124 over terminals 155 and 156. Thus, the beam will be caused to move across the screen in a direction having two perpendicular components corresponding to the two axes 30 selected by the system 134. Since the reflected signals are effectively applied to the beam modulation terminal 154, bright spots will appear on the screen at positions 35 corresponding to the received echoes.

It is to be understood that, when the apparatus is in use, the probe will normally be moved manually to scan the desired 40 portion of the patient. Accordingly, the values stored in the shift registers 147 and 148 will continually change to take account of movements of the probe. The sequence of events as controlled by the logic system 45 127 is as follows. The shift registers 147 of the three time-base units 129, 130 and 131 are cleared and the pulse generator 142 is triggered to cause a pulse to be transmitted from the bead 36, so that three new 50 values of d1 are transferred to, and stored in, the three shift registers 147. The pulse generator 120 is then triggered to transmit a sound pulse into the patient, so that echoes are received and corresponding 55 signals are applied to the terminal 154 of the display system. Thus, the beam of the cathode-ray-tube in the display system will be deflected along a line commencing from a point on the screen, the position of which 60 is determined by the values stored in the shift registers 147 of the time-base units associated with the two coordinates selected by the display selection system 134. The direction in which the beam travels across 65 the screen from this initial point will depend

on the values previously stored in the shift registers 148 of the same two time-base units. The shift register 148 is now cleared and the pulse generator 143 is triggered, so that a sound pulse is transmitted by the 70 bead 37, so that three values of d1-d2 are stored in the shift registers 148 of the three time-base units 129, 130 and 131. The pulse generator 120 is then again triggered to transmit a further sound pulse into the 75 patient. The echoes from this further pulse are displayed on the cathode-ray-tube, using the new value of d1-d2 and the previous value of d1. The sequence continues in this manner with a sound pulse being 80 transmitted into the patient after each new set of values of d1 has been stored and also after each new set of values of d1-d2 has been stored.

In one particular system the ultrasonic 85 frequency used for the pulses transmitted by the probe 18 is 1.5 MHz; the clock frequency used is approximately 22 MHz; the repetition rate of the system is approximately 1500 Hz; the sound velocity in the 90 tank is 1500 metres per second and the bead separation is 32 mm. Further, the maximum value of d1 is 168 mm on the Z axis and 122 mm on the X and Y axes, while the maximum value of d2 is 200 mm 95 on the Z axis of 154 mm on the X and Y axes.

It is to be understood that the system is capable of providing more information than can conveniently be displayed by the 100 simple display system 124. Thus, it is possible for the operator to carry out a three-dimensional scan instead of a simple two-dimensional scan. One method of providing a meaningful display of a three- 105 dimensional scan is to use two halves of a cathode-ray tube screen in time-division multiplex to display the complete left and right eye pictures alternately, the two pictures being modified to give a true 110 stereoscopic pair of images. Accordingly, the display selection unit 134 can be arranged, when required, to manipulate the information supplied to it in order to apply the corresponding signals to the deflection 115 plates of the display unit.

The two coordinate transformation networks 122 and 123 are also provided to manipulate the information obtained from the three time-base units. The operator of 120 the scanner is able to direct the beam into any tissue structures within a volume approximately equal to a cube of 500 mm side surrounding the patient's trunk. If the operator carries out, for example, a plane 125 scan along the mid-line of the patient, then this can be displayed as a conventional mid-line longitudinal section by adjusting the coordinate transformation networks to cause the display system to produce a picture 130

as seen from the patient's side, or in other words, from along the X axis. Similarly, a conventional transverse scan can be displayed if the coordinate transformation networks are adjusted to cause the display system to present the picture as seen along the Z axis.

If the external controls are put into a position intermediate between the transverse and longitudinal settings, then the echo pictures of the patient will be seen from an oblique viewpoint. Transverse scans made with the controls set in this way would appear in oblique projection parallel to the end faces of the cube referred to above. Scans at different levels would appear in their correct relative positions and, though they might overlap, the relationship between the different parts of the same tissue structure appearing in both scans would be made obvious. If a longitudinal scan was then made, it would intersect the two transverse scans in the proper places. Since composite pictures of this nature can be difficult to interpret, the gate 126 is used to cut out all echoes except those occurring at a selected depth or depths.

The gain control 125 is provided to adjust the gain of the receiving amplifier 122 in a predetermined manner after the transmission of each sound pulse into the patient. Thus, for example, the gain may be progressively increased, if desired, after the transmission of each pulse, so that all signals applied to the detector 123 have substantially constant values if they are received from equally reflecting surfaces irrespective of the distance travelled by the sound through the patient.

It is to be understood that various modifications be made in the apparatus described without departing from the scope of the invention as defined in the appended claims. For example, in the apparatus described and illustrated, one of the transducers is movable in the tank in order to reproduce motion of the probe along one axis, whereas it is, of course, to be understood that more than one of the transducers may be movable. In particular, if desired, the wave transmitters could be stationary relative to the tank, while the three transducers are movable to reproduce movements of the probe along mutually perpendicular axes. In such a system the probe could be fixedly mounted on the boom and the two wave transmitters could be fixedly mounted on the extension of the boom. Further, the tank could be mounted so that it is movable along three coordinate axes and the movements of the tank could be reproduced by corresponding movements of the three transducers within the tank on a reduced scale.

In another possible modification of the apparatus in accordance with the invention, the longitudinally extending probe which directs a single beam of ultrasonic pulses into the patient is replaced by a probe in the form of an array which produces a plurality of beams, the directivity axes of which are parallel and coplanar. This multi-element array may be mounted on the boom in the same way as the single beam probe, but the measuring device serves to produce electrical signals representing the position of the plane containing all said directivity axes rather than the position of a single directivity axis. For this purpose a third wave transmitter may be mounted on the boom extension, the three wave transmitters being located in a plane which corresponds to the plane containing the directivity axes. With such an arrangement the various beams of ultrasonic energy are produced in succession and the reflections from the various beams are used to produce an image of the reflecting surfaces intersected by the successive beams.

WHAT WE CLAIM IS:—

1. Apparatus for the ultrasonic examination of bodies having non-planar surfaces, including an ultrasonic probe mounted on one end of a boom so that it is movable around the body to be examined, at least one wave transmitter mounted on the opposite end of the boom in such a way that it follows the movements of said probe, and a plurality of wave receivers arranged to receive wave energy from said wave transmitter or transmitters and convert it into electrical signals representing the instantaneous position of the probe in a coordinate system.

2. Apparatus as claimed in Claim 1, wherein said wave transmitter is, or said wave transmitters are, arranged to transmit ultrasonic pulses and said receivers are ultrasonic transducers.

3. Apparatus as claimed in Claim 2, including three ultrasonic transducers, each having a plane receiving surface, said three surfaces being mutually perpendicular and thus defining a system of orthogonal axes, and wherein the electrical signals represent the time taken for ultrasonic pulses to travel from the wave transmitter, or transmitters, to each of the three transducers.

4. Apparatus as claimed in Claim 3, including two wave transmitters mounted and controlled so that the line joining their centres is oriented to correspond to the attitude of an axis in the probe, and means for producing electrical signals defining the orientation of the line joining the transmitters, said signals being derived from the differences in the times taken for ultrasonic energy to travel from the two transmitters to the three transducers.

5. Apparatus as claimed in any of the preceding Claims, wherein the probe is longitudinally extending and directs a beam of ultrasonic pulses into the body and receives reflected pulses from the body, wherein the probe is mounted on the boom so that the probe is pivotable about first and second mutually perpendicular axes intersecting in a point fixed with reference to the boom, said boom being mounted on a column so that the boom is pivotable about a third axis perpendicular to the axis of the boom and a fourth axis perpendicular to said third axis, said third and fourth axes intersecting in a point fixed with reference to the column, wherein means are provided to produce electrical signals defining the instantaneous position of a point on the longitudinal axis of the probe and the instantaneous attitude of said axis with reference to the coordinate system.

6. Apparatus as claimed in Claim 5, wherein the boom is mounted so that it has limited rotational freedom about its own axis.

7. Apparatus as claimed in any of Claims 1 to 4, wherein the probe is longitudinally extending and directs a beam of ultrasonic pulses into the body and receives reflected pulses from the body, wherein the probe is mounted on the boom so that the probe is pivotable about at least one axis fixed with reference to the boom, said boom being mounted on a column so that the boom has limited rotational freedom about the axis of the boom and is also pivotable about a third axis perpendicular to the axis of the boom and a fourth axis perpendicular to said third axis, said third and fourth axes intersecting in a point fixed with reference to the column, wherein means are provided to produce electrical signals defining the instantaneous position of a point on the longitudinal axis of the probe and the instantaneous attitude of said axis with reference to the coordinate system.

8. Apparatus as claimed in claims 5 to 7, wherein three electrical signals are produced, each in the form of a ramp, the initial level of which is indicative of the instantaneous position of said point in the probe relative to one axis of a system of three orthogonal axes and the slope of which is indicative of a component of the velocity of the beam along the longitudinal axis of the probe.

9. Apparatus as claimed in any of claims 5 to 8, including first and second wave transmitters mounted and controlled so that the instantaneous position of the first wave transmitter relative to a plurality of receivers corresponds to the instantaneous position of said point in the probe so that the line joining the centres of the first and second wave transmitters is oriented to correspond

to the attitude of the axis of the probe relative to said coordinate system, said receivers being arranged to receive wave energy from said transmitters and convert said energy into said electrical signals.

10. Apparatus as claimed in claim 9, wherein said wave transmitters are arranged to transmit ultrasonic pulses and said receivers are ultrasonic transducers, wherein there are three transducers, each having a plane receiving surface, said three surfaces being mutually perpendicular and thus defining a system of orthogonal axes, and wherein the electrical signals represent the time taken for ultrasonic pulses to travel from the first wave transmitter to each of the three transducers and also represent the differences in the times taken for the ultrasonic energy to travel from the two wave transmitters to each of the three transducers.

11. Apparatus as claimed in claim 10, wherein the two wave transmitters are mounted and controlled so that they follow the angular movements of the probe relative to the boom and also follow the movements of the boom relative to the column.

12. Apparatus as claimed in claim 11, wherein said column has limited freedom of translational movement along an axis perpendicular to the axis of the column.

13. Apparatus as claimed in claim 12, wherein the receiving surface of one of the transducers is perpendicular to the axis along which the column is movable, and wherein means are provided to cause this transducer to copy the movement of the column.

14. Apparatus as claimed in any of claims 9 to 13, wherein the angular movements of the line joining the two wave transmitters are equal to the angular movements of the probe relative to the boom, but the translational movements of the two transmitters produced by angular movement of the boom relative to the column are proportional to the corresponding translational movements of the probe on a reduced scale.

15. Apparatus as claimed in any of claims 7 to 14, wherein the two wave transmitters are mounted in a tank containing an acoustically transmissive fluid, said transmitters being in the form of beads designed to produce spherical acoustic wave trains, and wherein each of the transducers, which are also mounted in the tank, consists of a flat plate, the overall dimensions of the plates being such that any perpendicular erected through either bead on to the plane of one of the transducer surfaces always lies within the boundary of the respective plate within the limits of motion of the beads.

16. Apparatus as claimed in claim 15, 130

wherein each of the transducers consists of a co-planar mosaic of flat plates electrically connected in series.

17. Apparatus as claimed in claims 7 to 16, wherein the wave transmitters are mounted on wands carried on a rearward continuation of the boom.

18. Apparatus as claimed in claim 17, wherein the wands carrying the two beads at their free ends project from a shaft which is rotatable in an angle member, which is itself rotatable about an axis which intersects the axis of the shaft at right angles thereto, and wherein the rotational movements of the probe about the first and second axes are transmitted to the shaft and the rotatable member respectively.

19. Apparatus as claimed in any of claims 7 to 18, wherein the electrical signals are applied to three individual time-base units controlled by a logic system, wherein the outputs of the three time-base units are passed through a display selection system to the deflector plates of a display system, which is also controlled by further electrical signals derived from echoes received from the body as the result of reflection of the ultrasonic pulses from the probe.

20. Apparatus as claimed in claim 19, wherein the outputs of the three time-base units are passed to the display selection system through at least one coordinate transformation network.

21. Apparatus as claimed in claim 19 or claim 20, wherein each of said time-base units includes a digital counter which is stepped up from the instant when each pulse is transmitted by the first of said wave transmitters and stopped when the said pulse is received by a respective one of said receivers, and which is stepped down from the instant when each pulse is

transmitted by the second of said wave transmitters and stopped when the said pulse is received by the said receiver.

22. Apparatus as claimed in claim 21, wherein the number registered by the said counter after it has been stepped up is stored in a first shift register and the number registered by said counter after it has been stepped down is stored in a second shift register, wherein the numbers stored in said first and second shift registers are converted to analog signals in first and second digital-to-analog converters, wherein the output of said second digital-to-analog converter controls the slope of a ramp signal produced by an integrator, and wherein the output of the first digital-to-analog converter is added to the output of said integrator in a summing amplifier.

23. Apparatus as claimed in claim 22, wherein an ultrasonic pulse is transmitted from said probe into said body after each pulse has been transmitted by said first wave transmitter and also after each pulse has been transmitted by said second wave transmitter.

24. Apparatus as claimed in claim 23, wherein the ramp signal from said integrator is held at zero by a reset signal from said logic circuit until each ultrasonic pulse is transmitted into said body.

25. Apparatus for ultrasonic examination of bodies having non-planar surfaces, substantially as hereinbefore described with reference to, and as illustrated in, the accompanying diagrammatic drawings.

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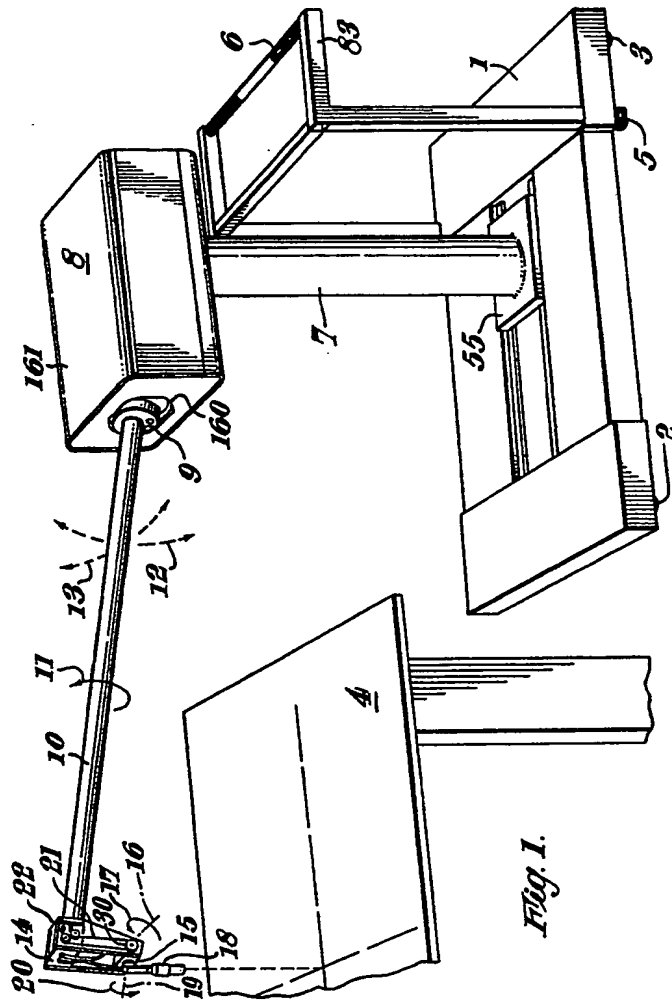
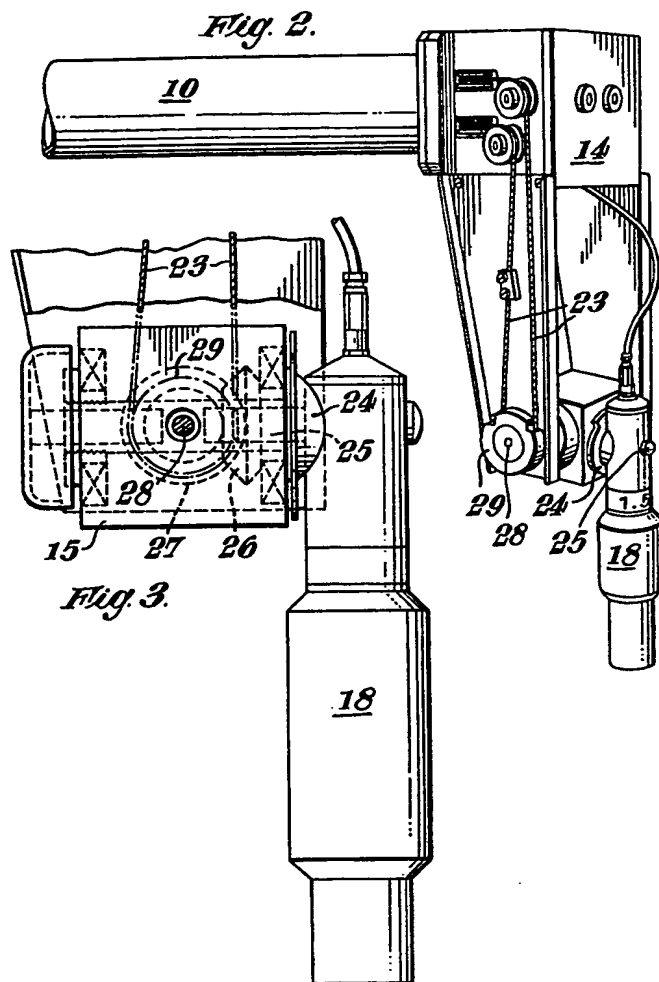


Fig. 1.



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COMPLETE SPECIFICATION

10 SHEETS

This drawing is a reproduction of
the Original on a reduced scale

Sheet 3

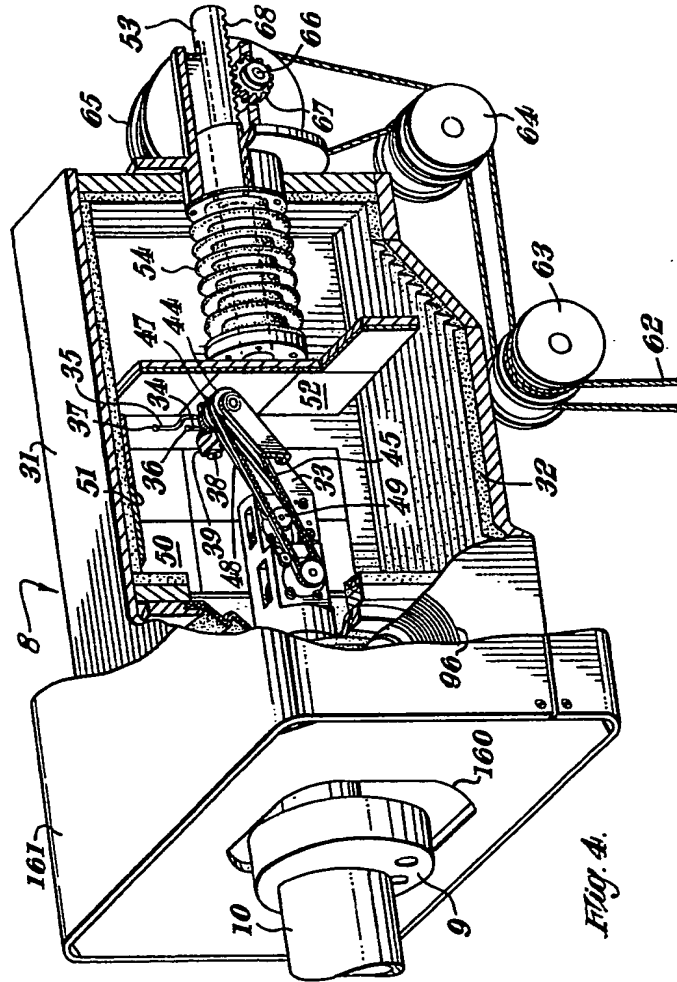
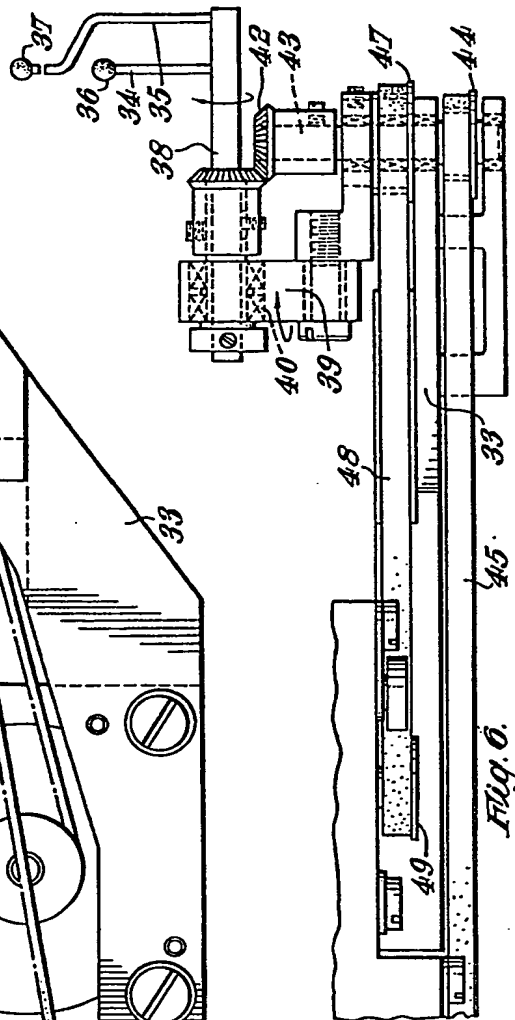
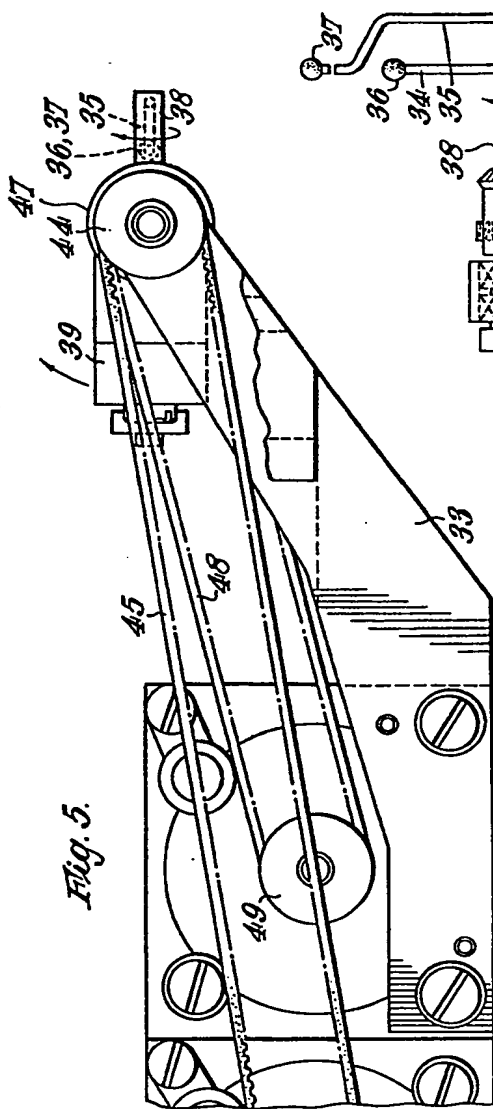
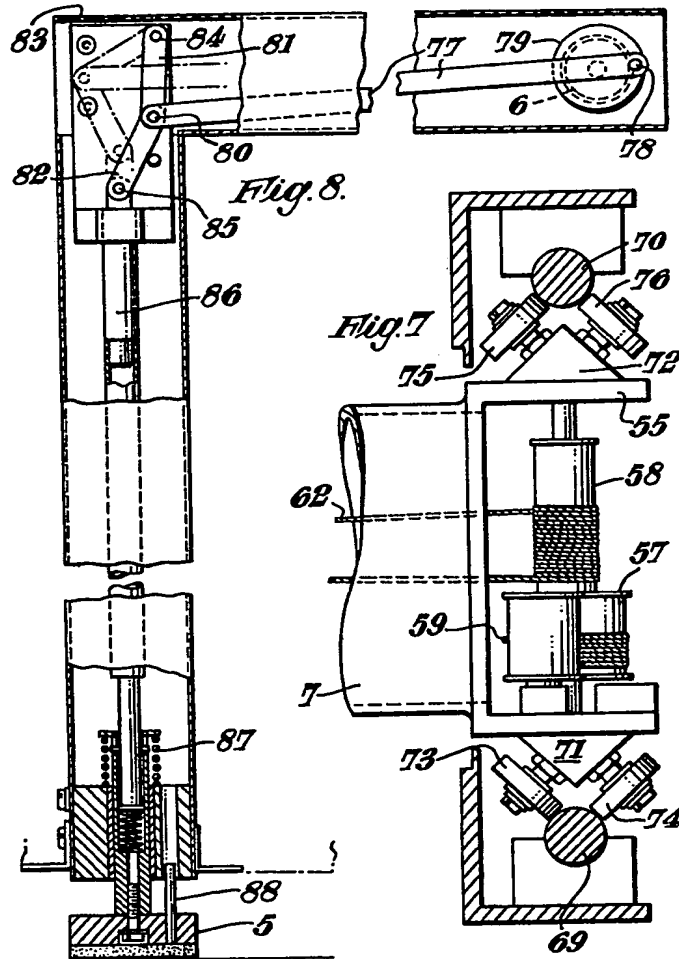
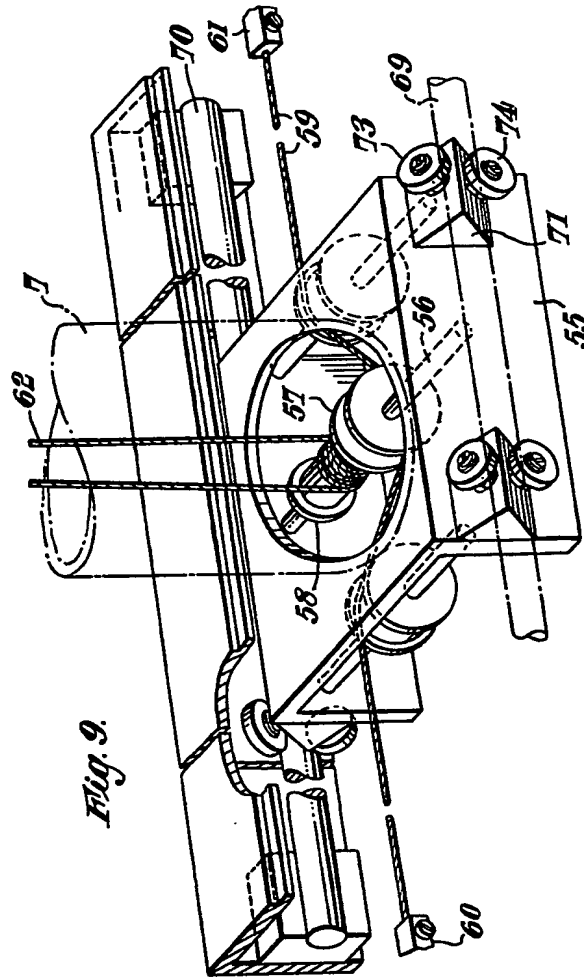
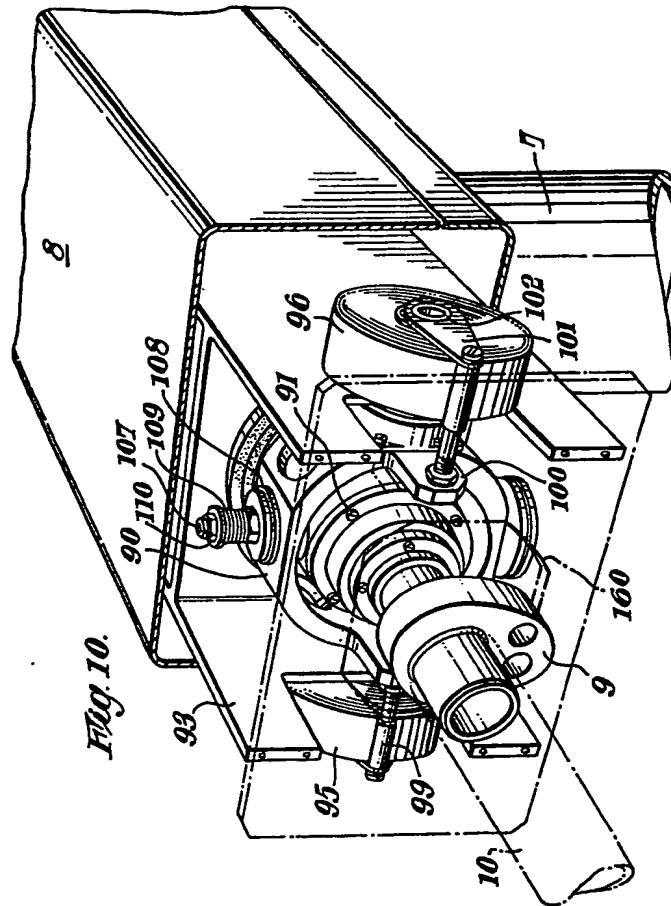


Fig. 4.









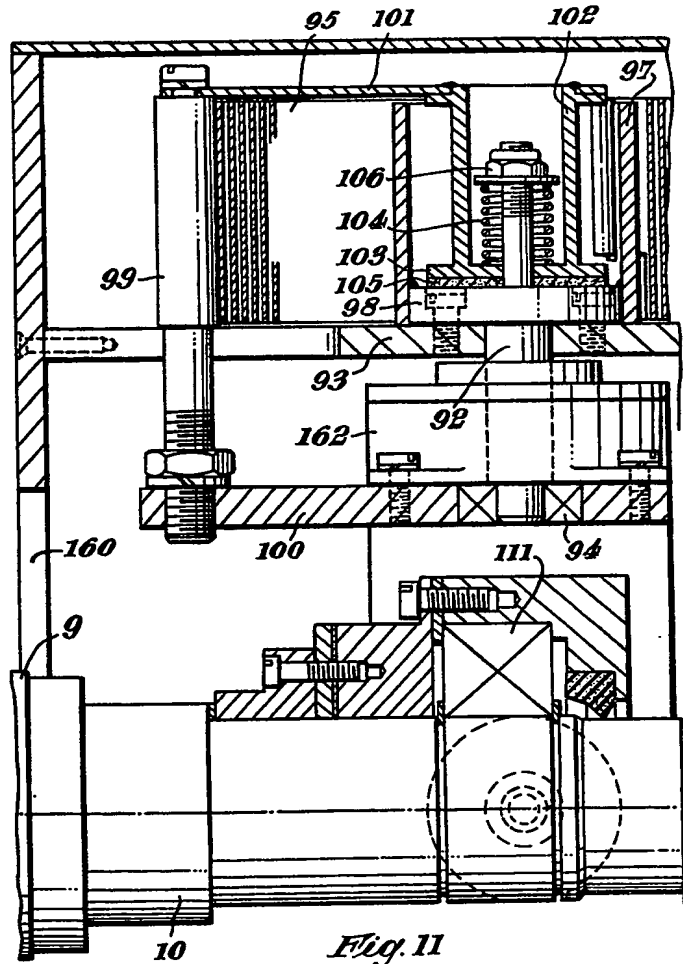


Fig. 11

